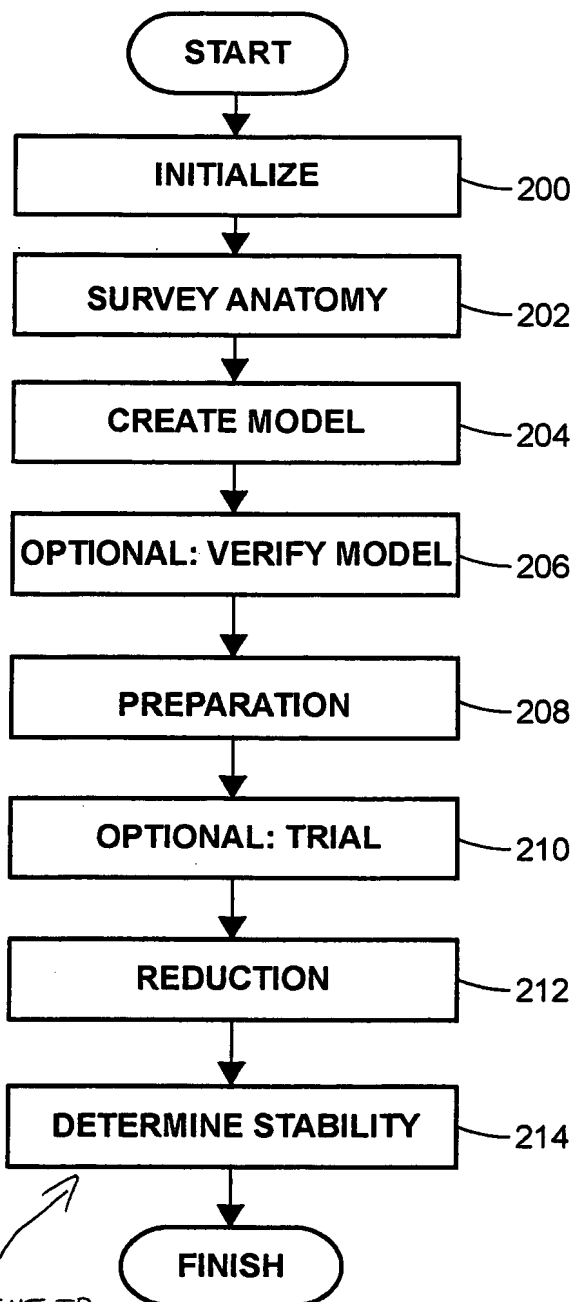




FIG. 2



MANIPULATE JOINT TO
DETERMINE STABILITY
AND RANGE OF MOTION



FIG. 2

